

FIG. 1

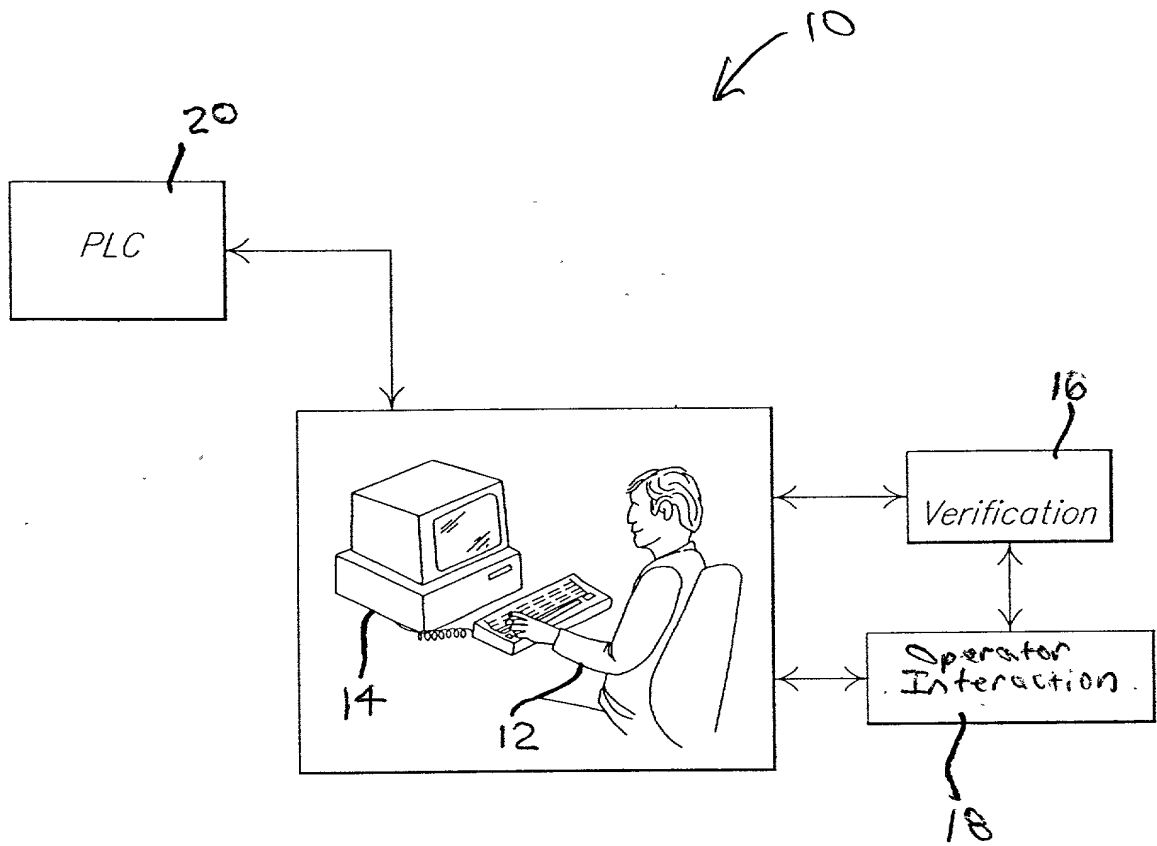
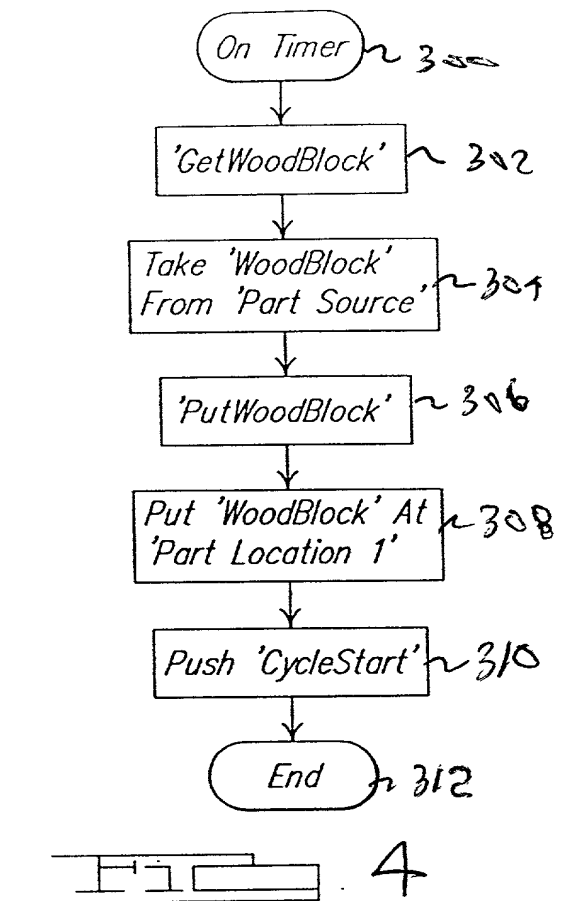
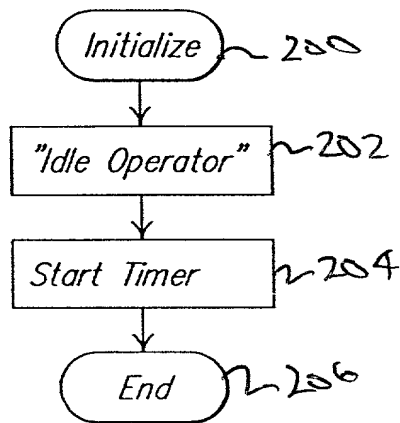
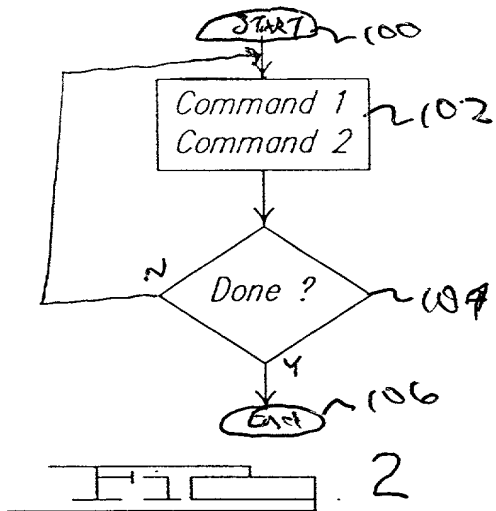


FIG. 1.



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graph TD
    subgraph Station_0 [Station 0]
        S0_1([Pusher Moves Part]) --> S0_2[Part On Transfer Bar]
        S0_2 --> S0_3([Part Moves Forward])
        S0_3 --> S0_4([Part Moves Up])
        S0_4 --> S0_5[Part At Top]
        S0_5 --> S0_6([Part Drops To Transfer Bar])
        S0_6 --> S0_7[Part At Workspace 1]
    end
    subgraph Station_1 [Station 1]
        S1_1([Part Moves Forward 2]) --> S1_2([Part Moves Up 2])
        S1_2 --> S1_3[Part At Top 2]
        S1_3 --> S1_4([Part Drops To Transfer Bar 2])
        S1_4 --> S1_5[Part At Workspace 2]
    end
    S0_7 --> S1_1
```

The flowchart illustrates a two-station robotic assembly process.   
**Station 0:**   
1. **Pusher Moves Part** (Step 50, oval) leads to **Part On Transfer Bar** (Step 52, rectangle).   
2. **Part Moves Forward** (Step 54, oval) leads to **Part Moves Up** (Step 56, oval).   
3. **Part Moves Up** (Step 56, oval) leads to **Part At Top** (Step 58, rectangle).   
4. **Part At Top** (Step 58, rectangle) leads to **Part Drops To Transfer Bar** (Step 60, oval).   
5. **Part Drops To Transfer Bar** (Step 60, oval) leads to **Part At Workspace 1** (Step 62, rectangle).   
**Station 1:**   
6. **Part Moves Forward 2** (Step 64, oval) leads to **Part Moves Up 2** (Step 66, oval).   
7. **Part Moves Up 2** (Step 66, oval) leads to **Part At Top 2** (Step 68, rectangle).   
8. **Part At Top 2** (Step 68, rectangle) leads to **Part Drops To Transfer Bar 2** (Step 70, oval).   
9. **Part Drops To Transfer Bar 2** (Step 70, oval) leads to **Part At Workspace 2** (Step 72, rectangle).   
A transition line connects the end of Station 0 (Step 62) to the start of Station 1 (Step 64).

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